

## CLAIMS

Please amend claims 1, 6, 7, 11, 14-16, 21-23 and cancel claims 3, 13 and 18 as shown below.

1. (Currently amended): A method for guiding an end effector to a target position within a person, the end effector being spatially associated with a robot coordinate system, the method comprising:

generating a plurality of digital images of an interior anatomy of the person when the person has a predetermined respiratory state, ~~the digital images being spatially associated with a digital image coordinate system;~~

indicating a skin entry position on at least one of the digital images;

indicating the target position on at least one of the digital images;

determining a first trajectory path based on the skin entry position and the target position in a digital image coordinate system associated with the plurality of digital images;

~~registering the spatial relationship between the end effector and the robot coordinate system with the spatial relationship between the end effector and the digital image coordinate system via a fiducial component associated with the end effector and visible in the digital images, thereby linking the end effector to the digital image coordinate system; and~~

~~in response to the registering, movement of the fiducial component in the digital image coordinate system, and points specified in the digital image coordinate system,~~

determining a second trajectory path in the robot coordinate system based on the first trajectory path and at least one transformation matrix for transforming coordinates in the digital image coordinate system to coordinates in the robot coordinate system;

monitoring a respiratory state of the person to obtain a monitored respiratory state;  
and

moving the end effector along the second trajectory path toward the target position when a difference between the monitored respiratory state and the predetermined respiratory state is less than or equal to a threshold value the person has substantially the predetermined respiratory state and stopping movement of the end effector when the difference between the monitored respiratory state and the predetermined respiratory state is not less than or equal to the threshold value the person does not substantially have the predetermined respiratory state;

wherein the determining a trajectory path comprises determining a trajectory path in the robot coordinate system by transforming a specified trajectory path in the digital image coordinate system via coordinate transformation.

2. (Original): The method of claim 1, wherein generating the plurality of digital images comprises:

moving the person within a scanning device along an axis; and,  
generating the plurality of cross-sectional digital images during the movement wherein each cross-sectional image is generated at a distinct axial position.

3. (Cancelled).

4. (Original): The method of claim 1, wherein the end effector is moved at a predetermined speed.

5. (Original): The method of claim 1, wherein the plurality of digital images comprises a plurality of computerized tomography images.

6. (Currently Amended): A system for guiding an end effector to a target position within a person, the end effector being spatially associated with a robot coordinate system, the system comprising:

a an infrared respiratory monitoring device for monitoring a respiratory state of the person to obtain a monitored respiratory state;

a scanning device configured to scan an interior anatomy of the person when the person has a predetermined respiratory state to generate scanning data;

a first computer generating a plurality of digital images based on the scanning data, the plurality of digital images being spatially associated with a digital image coordinate system;

a second computer configured to display the plurality of digital images, the second computer further configured to allow an operator to indicate a skin entry position on at least one of the digital images, the second computer further configured to allow the operator to indicate the target position on at least one of the digital images, the second computer further configured to determine a first trajectory path based on the skin entry position and the target position in the digital image coordinate system, the second computer further configured to register the spatial relationship between the end effector and the robot coordinate system with the spatial relationship between the end effector and the digital image coordinate system via a fiducial component associated with the end effector and visible in the digital images, thereby linking the end effector to the digital image coordinate system, the second computer further configured to determine the a second trajectory path in the robot coordinate system based on the first trajectory path and at least one transformation matrix for transforming coordinates in the digital image coordinate system to coordinates in the robot coordinate system by determining a

~~trajectory path in the robot coordinate system by transforming a specified trajectory path in the digital image coordinate system via coordinate transformation; and~~

an end effector insertion device having the end effector adapted to be inserted into the person, the second computer inducing the end effector insertion device to move the end effector along the second trajectory path toward the target position when a difference between the monitored respiratory state and the predetermined respiratory state is less than or equal to a threshold value the person has substantially the predetermined respiratory state and to stop movement of the end effector when the difference between the monitored respiratory state and the predetermined respiratory state is not less than or equal to the threshold value when the person does not substantially have the predetermined respiratory state.

7. (Currently Amended): The system of claim 6, wherein the infrared respiratory monitoring device comprises an infrared respiratory measurement device that detects a position of a chest of the person utilizing infrared light, to monitor the respiratory state of the person.

8. (Original): The system of claim 6, wherein the scanning device comprises a computerized tomography scanner and the plurality of digital images comprise a plurality of computerized tomography images.

9. (Original): The system of claim 6, wherein the end effector insertion device comprises an end effector driver configured to linearly move the end effector.

10. (Original): The system of claim 6, further comprising a positioning device operably coupled to the end effector insertion device for disposing the end effector insertion device at a predetermined position.

11. (Currently Amended): The system of claim 6, wherein the end effector insertion device can orient the end effector along the second trajectory path.

12. (Original): The system of claim 6, wherein the second computer is further configured to move the person within the scanning device for generating the plurality of digital images during the movement wherein each digital image is generated at a distinct axial position of the person.

13. (Cancelled).

14. (Currently Amended): The system of claim 6, wherein the second computer induces the end effector insertion device to move the end effector along the second trajectory path toward the target position at a predetermined speed.

15. (Currently amended): A system for guiding an end effector to a target position within a person, the end effector being spatially associated with a robot coordinate system, the system comprising:

a an infrared respiratory monitoring device for monitoring a respiratory state of the person to obtain a monitored respiratory state;

a scanning device configured to scan an interior anatomy of the person when the person has a predetermined respiratory state to generate scanning data;

a first computer generating a plurality of digital images based on the scanning data, the plurality of digital images being spatially associated with a digital image coordinate system, the first computer further configured to display the plurality of digital images, the first computer further configured to allow an operator to indicate a skin entry position on at least one of the digital images, the first computer further configured to allow the operator to indicate the target position on at least one of the digital images, the first computer further configured to determine a first trajectory path based on the skin entry position and the target position in the digital image coordinate system, the first computer further configured to register the spatial relationship between the end effector and the robot coordinate system with the spatial relationship between the end effector

~~and the digital image coordinate system via a fiducial component associated with the end effector and visible in the digital images, thereby linking the end effector to the digital image coordinate system; the first computer further configured to determine the a second trajectory path in the robot coordinate system based on the first trajectory path and at least one transformation matrix for transforming coordinates in the digital image coordinate system to coordinates in the robot coordinate system by determining a trajectory path in the robot coordinate system by transforming a specified trajectory path in the digital image coordinate system via coordinate transformation; and~~

~~an end effector insertion device having the end effector adapted to be inserted into the person, the first computer inducing the end effector insertion device to move the end effector along the second trajectory path toward the target position when a difference between the monitored respiratory state and the predetermined respiratory state is less than or equal to a threshold value the person has substantially the predetermined respiratory state and to stop movement of the end effector when the difference between the monitored respiratory state and the predetermined respiratory state is not less than or equal to the threshold value when the person does not substantially have the predetermined respiratory state.~~

16. (Currently amended): An article of manufacture, comprising:

a computer storage medium having a computer program encoded therein for guiding an end effector to a target position within a person, the end effector being spatially associated with a robot coordinate system, the computer storage medium including:

code for displaying and generating a plurality of digital images of an interior anatomy of the person when the person has a predetermined respiratory state, the plurality of digital images being spatially associated with a digital image coordinate system;

code for indicating a skin entry position on at least one of the digital images;

code for indicating the target position on at least one of the digital images;

code for determining a specified first trajectory path based on the skin entry position and the target position in the digital image coordinate system;

code for determining a second trajectory path in the robot coordinate system based on the first trajectory path and at least one transformation matrix for transforming coordinates in the digital image coordinate system to coordinates in the robot coordinate system by transforming the specified trajectory path in the digital image coordinate system via coordinate transformation;

~~code for registering the spatial relationship between the end effector and the robot coordinate system with the spatial relationship between the end effector and the digital image coordinate system via a fiducial component associated with the end effector and visible in the digital images, thereby linking the end effector to the digital image coordinate system; and~~

code for monitoring a respiratory state of the person to obtain a monitored respiratory state;

code for moving the end effector along the second trajectory path in the robot coordinate system toward the target position when a difference between the monitored respiratory state and the predetermined respiratory state is less than or equal to a threshold value the person has substantially the predetermined respiratory state; and

~~code for stopping movement of the end effector when the difference between the monitored respiratory state and the predetermined respiratory state is not less than or equal to the threshold value the person does not substantially have the predetermined respiratory state.~~

17. (Original): The article of manufacture of claim 16, wherein the code for displaying the plurality of digital images comprises:

code for scanning a predetermined region of the person along an axis; and,

code for generating the plurality of digital images during the movement wherein each digital image is generated at a distinct axial position.

18. (Cancelled).

19. (Original): The article of manufacture of claim 16, wherein the computer storage medium further includes code for moving the end effector at a predetermined speed into the person.

20. (Original): The article of manufacture of claim 16, wherein the plurality of digital images comprises a plurality of computerized tomography images.

21. (Currently amended): A method for guiding an end effector to a target position within a person, the end effector being spatially associated with a robot coordinate system, the person having an associated plurality of digital images that are spatially associated with a digital image coordinate system, comprising:

monitoring a respiratory state of a person during at least one respiratory cycle;

~~registering determining~~ the spatial relationship between the end effector and the robot coordinate system with the spatial relationship between the end effector and the digital image coordinate system via a fiducial component associated with the end effector and visible in the plurality of digital images, thereby linking the end effector to the digital image coordinate system;

determining a second trajectory path in the robot coordinate system by transforming a specified first trajectory path in the digital image coordinate system via coordinate transformation; and

~~in response to the registering and movement of the fiducial component in the digital image coordinate system,~~ moving the end effector along a the second trajectory path in the robot coordinate system toward the target position in the person when the person has substantially a predetermined respiratory state and stopping movement of the end effector when the person does not have substantially have the predetermined respiratory state.

22. (Currently Amended): The method of claim + 21, further comprising:

generating a gating signal having a defined logical level in response to the person having substantially the predetermined respiratory state;

wherein the moving the end effector occurs in response to the gating signal having the defined logical level; and

wherein the moving the end effector does not occur in response to the gating signal not having the defined logical level.

23. (Currently Amended): The method of claim 4 22, wherein

the moving of the end effector occurs in a plurality of steps, each step being in response to the person having substantially the predetermined respiratory state as determined by a gating signal having a defined logical level, until the end effector reaches the target position.

Please add new claim 24.

24. (New): A method for guiding an end effector to a target position within a person, the end effector being spatially associated with a robot coordinate system, the method comprising:

generating a plurality of digital images of an interior anatomy of the person when the person has a predetermined respiratory state;

determining a first trajectory path based on a skin entry position and a target position in a digital image coordinate system associated with the plurality of digital images;

determining a second trajectory path in the robot coordinate system based on the first trajectory path and at least one transformation matrix for transforming coordinates in the digital image coordinate system to coordinates in the robot coordinate system;

generating a first signal that is indicative of respiratory states of the person over time; and

moving the end effector along the second trajectory path toward the target position when an amplitude of the first signal is within a predetermined amplitude range, the predetermined amplitude range having an upper threshold value and a lower threshold

value, and stopping movement of the end effector when the amplitude of the first signal is not within the predetermined amplitude range.